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<input type="checkbox"/>	L7	L4 and position error	4
<input type="checkbox"/>	L6	L3 and l4	4
<input type="checkbox"/>	L5	(l3 or L4) and position error	11136
		(5944475 6213853 6213853 6227946 6242879 5833426 6024107 6073828 4854623 4897015 5007784 5429251 5452521 5607276 5613821 5651823 5664925 5746460 5778554 5783834 5789890 5795355 5803979 5810549 5870488 5905850 5954840 5967578 5993142 5993141 6012470 6037733 6059516 6059516 6085670 6121743 6164894 6202482 6205852 6213136 6213136 6256555 6267423 6275748 6283355 6293749 6298280 6326755 6350177 6360144).pn.	
<input type="checkbox"/>	L4		82
<input type="checkbox"/>	L3	(robot\$6 or articulat\$3 or automat\$6 or autonomous\$2 or CNC or machine\$2 or mechanical device or mechan\$6 or servomechan\$4) and position error	11136
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... outline a system developed for control of a PUMA 560 **robot arm** that uses a ... While operating with a PD control loop, the maximum **position error** (while tracking ...

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... perhaps the orientation error is not as important as the **position error** is ... we will present some test results concerning the simulated **robot arm** neural controller ...

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... Steady state error Set the torque (u) proportional to the **position error** $e_K u_p = \dots$ 7DOF anthropomorphic **robot arm** SARCOS dexterous arm 7 21 : $\mathfrak{R} \rightarrow \mathfrak{R}^f \dots$

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... n error, which is the difference between the actual position of the **robot arm** and the position commanded by the operator. This **position-error** force-reflection ...

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... The experimental results revealed a **position error** for the shoulder, elbow and wrist of 0.60.6 mm, 0.50 ... "Human Motion Analysis Based on a **Robot Arm** Model," Proc ...

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[\[PDF\] CS545—Contents I](#)

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... 1979 Japan introduces the SCARA (Selective Compliance Assembly **Robot Arm**); Digital Electronic Automation (DEA) of Turin, Italy ... **position error** (proportional) ...

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... The sources of **position error** that affect accuracy can be grouped into four ... of representation of resolution, accuracy, and repeatability of a **robot arm** [Kor85 ...

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... For our robot, a seven DOF anthropomorphic **robot arm**, the inverse dynamics model receives 21 inputs and outputs 7 torque ... variable q. The **position error** of the ...

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... becomes the model input. The model is illustrated in Figure 2. Fig. 2 . Nonlinear model of the **robot arm**. The damping and the nonlinear ...

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Page 1. PERIODICA POLYTECHNICA SER. EL. ENG. VOL. 45, NO. 3-4, PP. 195-209 (2001)

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"robot arm" and "position error"

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